Appln. No. 10/602,958   Attorney Docket No. 10541-1722

I. Amendments to the Specification

Please replace Paragraph [0038] with the following paragraph:

[0038]   where $x \in R^n$ is the state variable, $y \in R^p$ is the measured output, $z \in R^q$ is a linear combination of the state variables to be detected, $d \in R^m$ is the disturbance, u is the control input, $A(v)$, $B_1(v)$, $C_1(v)$, $C_2(v)$, and $D_{21}(v)$ are matrices of the appropriate dimensions that describe the nominal system, $\Delta A(v)$, $\Delta B_1(v)$, $\Delta C_2(v)$ and $\Delta D_{21}(v)$ represent the parameter uncertainties, and v represents vehicle speed. As is known in the art, the equation $x \in R^n$ means that x is an element in the set of R^n. It is a description for the steer-by-wire system with non-linearity and uncertainty. The equation is linear at each nominal vehicle speed, $v = v_0$.

-2-